IN THE SPECIFICATION

Please amend paragraph 16 of the specification as follows:

Referring now to Fig. 2, the vibratory mechanism 26 is contained within a housing 46 that is coaxially supported within the first compacting drum ~~26~~ 14 in a known manner. The vibratory mechanism 26 includes a first/inner eccentric weight 50 and a second/outer eccentric weight 52 that are connected to an inner shaft 54 and an outer shaft 56 respectively. Motor 28 drives the inner and outer shafts 54,56 to supply rotational power to the first vibratory mechanism 26 thereby imparting a vibratory force on compacting drum 14. More specifically, the inner shaft 54 is driven by motor 28 via an inner flexible coupling 60, and the outer shaft 56 is driven by motor 28 via an outer flexible coupling 62, as shown in Fig. 2.

A1

Please amend paragraph 18 of the specification as follows:

The moveable ring gear 86 is connected through a pinion gear 90 to a phase control device 92 mounted on the gearbox 70 in a conventional manner, as shown in Fig. 3. Phase control device 92 is a motor 93 with a rotary sensor 94 attached to an output shaft 95 to provide an indication of position to a controller 100. As a first alternative to the phase control device ~~motor~~ 92, a hand wheel 96 connected to the pinion gear 90 will function in a similar manner. As a second alternative to the phase control device 92, an actuator 102 for driving the moveable ring gear 86 in rotation is shown in Fig. 4. Actuator 102 has a rack 104 positioned between two linear actuators 106,108 operation in opposition to each other. Linear actuators 106,108 can be hydraulic cylinders or other electrically controlled devices for supplying linear movement to the rack 104. Dual proximity sensors 110, only one shown in Fig. 4 would sense the teeth 112 over the length of rack travel. For example, the rack might have 18 teeth. With dual proximity sensors 110 sensing the teeth ~~110~~ 112, there would be 72 "states" (2.5° resolution) over the length of the rack travel. This is commonly called a quadrature output and can be used to sense both direction and position (via absolute count) in machine control theory. Other types of position sensors could be used for example, linear

A2

A2 Cancl.

variable displacement transducers (LVDT), direct resistance linear rheostats, rotary encoders in combination with a device for converting linear movement into rotational movement, and sonar devices.